AMENDMENTS TO THE CLAIMS

1. (Currently Amended) A method for searching a return path of a moving object for use in a navigation system, the method comprising ~~the steps of~~:

searching and storing an original driving path of the moving object, and guiding the moving object along the searched driving path;

deciding whether the moving object is deviated from the driving path;

~~when the moving object is deviated from the driving path,~~ deciding a start point and return points for returning the moving object on the original driving path, <u>when the moving object is deviated from the driving path</u>;

~~after searching respective paths from the start point to the return points,~~ deciding a shortest path as an optimum return path, <u>after searching respective paths from the start point to the return points</u>; and

guiding the moving object to the original driving path along the decided return path<u>,</u>

<u>wherein the start point of the moving object on a deviated path is a present position of the moving object or a position that a user of the moving object inputs, and the return points include adjacent return points to a position that corresponds to a deviation point used as a reference for the driving path of the moving object multiplied by a predetermined constant.</u>

2. (Canceled)

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3. (Currently Amended) The method according to claim 1, wherein the return points of

the moving object ~~are comprised of~~ include at least one node existing on a path from ~~a~~ the

deviation point of the driving path to a destination.

4. (Canceled)

5. (Currently Amended) The method according to claim 3, wherein the return points ~~are~~

~~comprised of~~ include a last deviation point from the driving path, a deviated distance from the

deviation point, and at least one node existing on a digitized map, ~~particularly~~including at a

distant position in a direction from the deviation point of the driving path to the destination by a

predetermined multiple of the deviated distance.

6. (Original) The method according to claim 1, wherein the optimum return path is

decided by searching and storing respective paths that connect the start point of the deviated

moving object from the driving path to the return points existing on the driving path, and by

deciding a shortest path as the optimum return path.

7. (Original) The method according to claim 1, wherein a search result of the return path

is provided to the user of the moving object, and on the basis of distance and time information to

return on the searched return path from a present position, the user decides a return path.

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8. (Original) The method according to claim 1, wherein the return path of the moving

object is greater than a deviated distance of the moving object, and less than a distance from the

deviation point to a destination.

9. (Currently Amended) The method according to claim 1, ~~wherein return path searching~~

~~for the moving object~~ <u>searching the respective paths</u> is performed by using GPS position data

transmitted from a plurality of GPS satellites, and digitized map data.

10. (Currently Amended) The method according to claim 1, wherein the guidance of the

moving object to the return path comprises ~~substeps of~~:

confirming whether the moving object is returning on the original driving path; and

when the moving object returns on the original driving path, guiding the moving object to

continue travel along the original driving path.

11. (Currently Amended) A navigation system, comprising:

a GPS receiving means for receiving position data transmitted from a plurality of GPS

satellites;

a map data storing means for storing digital map data;

a user input means;

a display and a voice output means for providing a user of a moving object with a driving

path; and

a main control means for setting a driving path from a present position of the moving

object to a destination on the basis of the GPS position data and the digital map data, storing the

driving path, guiding the user to the driving path, and when the moving object is deviated from

the driving path originally set, for searching and deciding a shortest optimum return path and

guiding the user to the decided return path,

wherein the return path is selected among return paths that respectively connects a last

deviation point from the driving path due to deviation of the moving object to a set of return

points that includes adjacent nodes positioned on the driving path, in which the nodes are distant

from the deviation point by a predetermined distance and the main control means designates the

start point of the moving object on the deviated path as a present position of the moving object or

a position the user of the moving object inputs.

12. (Canceled)

13. (Canceled)

14. (New) A navigation system, comprising:

a GPS receiver configured to receive position data transmitted from a plurality of GPS

satellites;

a map data memory configured to store digital map data;

a user input unit configured to receive user input;

a display and a voice output unit configured to provide a user of a moving object with a

driving path; and

a main control processor configure to set a driving path from a present position of the

moving object to a destination on the basis of the GPS position data and the digital map data, to

store the driving path, to guide the user to the driving path, and when the moving object is

deviated from the driving path originally set, to search and decide a shortest optimum return path

and guiding the user to the decided return path,

wherein the return path is selected among return paths that respectively connects a last

deviation point from the driving path due to deviation of the moving object to a set of return

points that include adjacent nodes positioned on the driving path, in which the nodes are distant

from the deviation point by a predetermined distance and the main control processor designates

the start point of the moving object on the deviated path as a present position of the moving

object or a position the user of the moving object inputs.

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